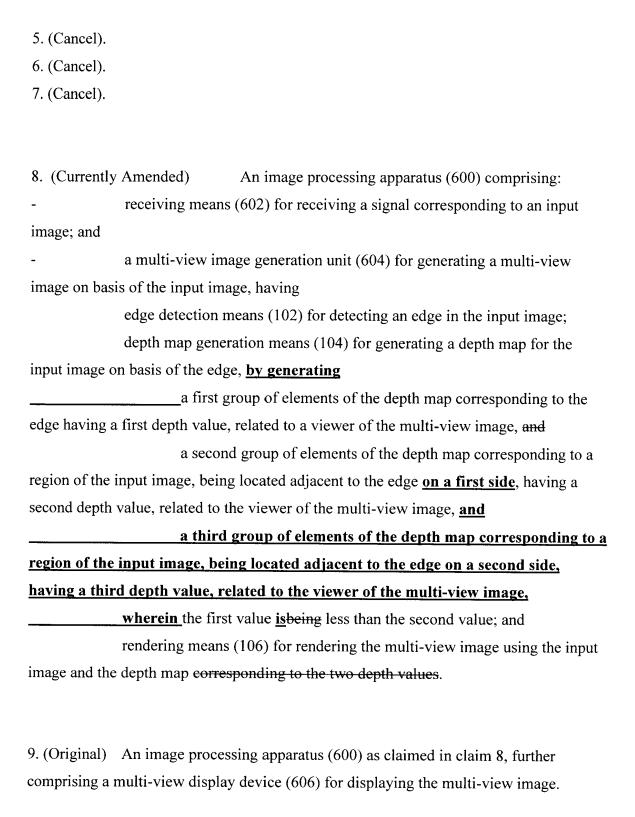
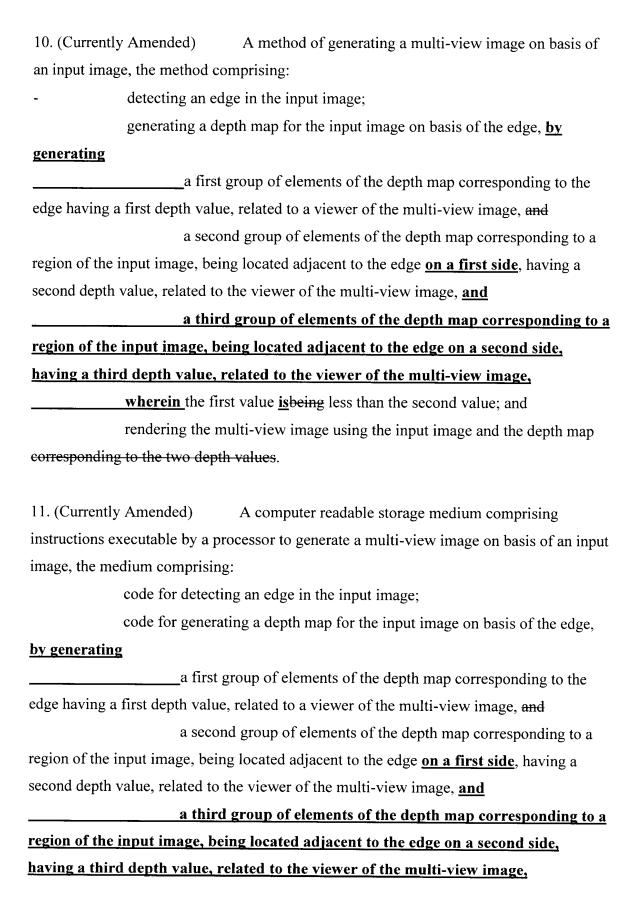
IN THE CLAIMS

1. (Currently Amended)	A multi-view image generation unit (100, 200) for
generating a multi-view image	e on basis of an input image, the generation unit
comprising:	
edge detection	means (102) for detecting an edge in the input image;
depth map gene	eration means (104) for generating a depth map for the
input image on basis of the ed	ge, by generating
a first	group of elements of the depth map corresponding to the
edge having a first depth value	e, related to a viewer of the multi-view image, and
a secon	nd group of elements of the depth map corresponding to a
region of the input image, being	ng located adjacent to the edge on a first side, having a
second depth value, related to	the viewer of the multi-view image, and
a thire	group of elements of the depth map corresponding to a
region of the input image, being located adjacent to the edge on a second side,	
having a third depth value, r	related to the viewer of the multi-view image,
wherein the first value isbeing less than the second value; and	
rendering means (106) for rendering the multi-view image using the input	
image and the depth map eorre	esponding to the two depth values.
2. (Previously Presented)	A multi-view image generation unit (100) as claimed in
claim 1, wherein the edge dete	ction means (102) is arranged to detect the edge by
computing pixel value differences between first pixel values of the input image and	
respective second pixel values	of a second input image, the input image and the second
input image belonging to a seq	uence of video images.
3. (Original) A multi-view in	nage generation unit (100) as claimed in claim 2, wherein
the first pixel values represent	one of color and luminance.

4. (Original) A multi-view image generation unit (100) as claimed in claim 2, wherein

the first depth value is a function of a first one of the pixel value differences.





wherein the first value isbeing less than the second value; and code for rendering the multi-view image using the input image and the depth map corresponding to the two depth values.